

WEST Search History

DATE: Saturday, August 11, 2007

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	<i>DB=PGPB,USPT,EPAB,JPAB,DWPI,TDBD; PLUR=YES; OP=ADJ</i>		
<input type="checkbox"/>	L21	dynamics same model and L18	51
<input type="checkbox"/>	L20	dyanamics and L18	0
<input type="checkbox"/>	L19	dyanamics same model and L18	0
<input type="checkbox"/>	L18	L16 and L17	141
<input type="checkbox"/>	L17	movement or trajectory and L16	2459930
<input type="checkbox"/>	L16	floor and zmp and L3	150
<input type="checkbox"/>	L15	floor and zmp and L14	0
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<input type="checkbox"/>	L13	motion pattern and L11	2
<input type="checkbox"/>	L12	motion pattern and stor\$3 and L11	0
<input type="checkbox"/>	L11	freedom and L10	5
<input type="checkbox"/>	L10	L8 and L9	6
<input type="checkbox"/>	L9	L8 and gait or gate	1122553
<input type="checkbox"/>	L8	('6580969' '6493606' '6463356' '6289265' '6243623' '5872893' '5841258' '5838130' '5594644' 'EP 1136193A' 'EP 1103451A')!.ABPN1,NRPN,PN,TBAN,WKU.	18
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<input type="checkbox"/>	L5	(legged robot or pet robot or humanoid near10 robot) motion and pattern and L4	0
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	(700/245 700/246 700/251 700/253 700/260 700/261 or 318/568.1 318/568.12 318/568.16 318/568.17 318/568.2 or 901/1 901/9 901/46 or 180/8.1 180/8.6 180/65.1 or 701/23 or 320/116 320/120 or 446/376 446/384).ccls.		
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END OF SEARCH HISTORY



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Key: IEEE JNL = IEEE Journal or Magazine, IEE JNL = IEE Journal or Magazine, IEEE CNF = IEEE Conference, IEE CNF = IEE Conference, IEEE STD = IEEE Standard

1. **A novel gait generation for biped walking robots based on mechanical energy constraint**
Asano, F.; Yamakita, M.; Kamamichi, N.; Zhi-Wei Luo;
Robotics and Automation, IEEE Transactions on
Volume 20, Issue 3, June 2004 Page(s):565 - 573
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2. **Some extensions of passive walking formula to active biped robots**
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Volume 4, Apr 26-May 1, 2004 Page(s):3797 - 3802 Vol.4
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3. **Biped Gait Generation and Control Based on a Unified Property of Passive Dynamic Walking**
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4. **Adaptive gait algorithm for IWR biped robot**
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5. **A study on the zero moment point measurement for biped walking robots**
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7. **A new method of desired gait synthesis in biped robot**
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9. **Reinforcement learning method-based stable gait synthesis for biped robot**
Hu Lingyun; Sun Zengqi;
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10. **A New Humanoid Robot Gait Generation Based on Multiobjective Optimization**
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11. **Motion control strategy for humanoid robot MIH-1**
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12. **A novel gait generation for biped walking robots based on mechanical energy constraint**
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13. **Unification of dynamic gait generation methods via variable virtual gravity and its control performance analysis**
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14. **Dynamic transition simulation of a walking anthropomorphic robot**
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